In the Claims:

1. [currently amended] A method of mobile device control comprising:

moving a surrogate under wireless control by a user;

during the moving, detecting unsuitable degradation of wireless communications of the wireless control; and

in response to the detecting and while the surrogate is still receiving the wireless communications, autonomously moving the surrogate to provide suitable wireless communications of the wireless control;

wherein the detecting comprises comparing a performance parameter associated with the wireless communications with a threshold.

2. [original] The method as claimed in claim 1 additionally comprising:

autonomously moving the surrogate along a previously determined route.

3. [previously presented] The method as claimed in claim 1 wherein:

autonomously moving the surrogate to provide suitable wireless communications of the wireless control occurs after passage of a period of time following the detecting of the degradation; and

the method further comprises after the detecting of the unsuitable degradation, the surrogate loitering near a location where the unsuitable degradation was detected during the passage of the period of time.

4-5. [canceled].

6. [previously presented] The method as claimed in claim 1 wherein:

autonomously moving the surrogate uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof; and

autonomously moving the surrogate uses waypoints back along a forward movement path for backtracking movement.

7. [currently amended] A method of mobile telepresencing comprising:

moving a surrogate under real-time wireless control by a user;

autonomously moving the surrogate to an area with adequate wireless coverage to regain wireless control when the wireless control is lost for a period of time; ~~and~~

while the surrogate is autonomously moving, activating a human perceptible indicator which is perceptible to humans in the presence of the surrogate; and

prior to autonomously moving the surrogate, determining that the loss of the wireless control has persisted for the period of time.

8. [canceled].

9. [currently amended] The method as claimed in claim 7 wherein:

losing wireless control includes degradation of the control to a threshold level;

autonomously moving the surrogate to regain wireless control occurs after [[a]] the period of time.

10. [previously presented] The method as claimed in claim 7 wherein:

autonomously moving the surrogate includes:

backtracking while measuring distance and avoiding collisions by the surrogate;

stopping the surrogate for an obstacle; and

resuming backtracking after removal of the obstacle.

11. [canceled].

12. [currently amended] The method as claimed in claim 7 wherein:

the autonomously moving the surrogate ~~to backtrack~~ uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof;

the autonomously moving the surrogate ~~to backtrack~~ uses a slower speed than forward speed; and

the autonomously moving the surrogate uses waypoints back along a forward movement path for backtracking movement considering the slower speed of backtracking.

13. [currently amended] A mobile device control system comprising:

a surrogate movable under wireless control by a user; and

a computer/transceiver system on the surrogate for moving the surrogate to regain wireless control independently of the wireless control after passage of a non-zero amount of time following a loss of the wireless control;

wherein the computer/transceiver system is configured to move the surrogate after the computer/transceiver system has determined that the loss has persisted for the non-zero amount of time.

14. [canceled].

15. [currently amended] The system as claimed in claim 13 wherein:

the computer/transceiver system is configured to autonomously move ~~for autonomously moving~~ the surrogate to regain wireless control ~~occurs~~ after the surrogate remains stationary for the non-zero amount of time.

16. [original] The system as claimed in claim 13 wherein:

the computer/transceiver system for autonomously moving the surrogate includes measuring distance and avoiding collisions by the surrogate.

17. [canceled].

18. [previously presented] The system as claimed in claim 13 wherein:

the computer/transceiver system uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof; and

the computer/transceiver system calculates waypoints back along a forward movement path for backtracking movement.

19. [currently amended] A mobile telepresencing system comprising:

a surrogate movable under wireless control by a user; and

a computer/transceiver system configured to determine ~~for determining~~ when the wireless control is lost and responsive to the determining, autonomously move ~~moving~~ the surrogate to an area not currently receiving adequate coverage of the wireless control, but in which the surrogate previously experienced adequate coverage of the wireless control, and wait in the area until ~~to regain~~ adequate coverage of the wireless control is regained.

20. [currently amended] The system as claimed in claim 19 wherein ~~additionally comprising~~:

the computer/transceiver system is configured to ~~for~~ autonomously ~~moving~~ move the surrogate along at least one of a previously determined route, a distance, a destination, a direction, or a combination thereof.

21. [currently amended] The system as claimed in claim 19 wherein:

the computer/transceiver system is configured to determine ~~for determining~~ degradation of the wireless control to a threshold level; and

the computer/transceiver system ~~for autonomously moving~~ is configured to autonomously move the surrogate to regain wireless control ~~occurs~~ after a period of time.

22. [currently amended] The system as claimed in claim 19 wherein:

the computer/transceiver system ~~for autonomously moving the surrogate~~ includes:

backtracking means for measuring distance and avoiding collisions by the surrogate during backtracking;

stopping means for stopping the surrogate for an obstacle; and

means for resuming backtracking after removal of the obstacle.

23. [canceled].

24. [previously presented] The system as claimed in claim 19 wherein:

the computer/transceiver system uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof for backtracking;

the computer/transceiver system provides a slower speed than forward speed for backtracking by the surrogate; and

the computer/transceiver system uses waypoints back along a forward movement path for backtracking movement considering the slower speed of backtracking.

25. [canceled]

26. [currently amended] The method as claimed in claim 1 ~~claim 25~~ wherein:

the detecting comprises determining that a current non-zero data rate at which the surrogate is successfully transmitting data via the wireless communications is less than a desired data rate.

27. [currently amended] The method as claimed in claim 26 further comprising:

prior to the detecting, wirelessly transmitting a video signal at or above the desired data rate from the surrogate to the user.

28. [currently amended] The method as claimed in claim 10 further comprising:

prior to the resuming of the backtracking, the surrogate sensing removal of the obstacle; and

wherein the resuming is responsive to the sensing.

29. [currently amended] The method as claimed in claim 1 ~~claim 25~~ wherein the detecting comprises determining that a current transmission delay associated with packets received by the surrogate is greater than an acceptable transmission delay.

30. [currently amended] The system of claim 13 wherein the computer/transceiver system is configured to detect the loss of the wireless control and to configure the surrogate to remain stationary ~~near the location~~ for the non-zero amount of time following the loss of the wireless control near a location at which the loss of the wireless control was detected.

31. [previously presented] The method of claim 7 wherein the surrogate comprises the human perceptible indicator.

32. [currently amended] The system of claim 13 wherein the computer/transceiver system is configured to detect the loss of the wireless control, to configure the surrogate to loiter for the non-zero amount of time following the loss of the wireless control near a location at which the loss of the wireless control was detected, and to monitor for return of the wireless control during the non-zero amount of time.

33. [previously presented] The system of claim 19 wherein the computer/transceiver system is configured to loiter in the area for the wireless control to return.

34. [previously presented] The method of claim 10 wherein the resuming backtracking comprises automatically without user intervention resuming backtracking.

35. [previously presented] The system of claim 22 wherein the means for resuming backtracking after removal of the obstacle comprises means for automatically without user intervention resuming backtracking after removal of the obstacle.

36. [new] The method of claim 7 wherein the period of time is at least two seconds.

37. [new] The system of claim 13 wherein the computer/transceiver system is configured to determine that a first non-zero data rate at which the surrogate is successfully transmitting data via the wireless control at a first moment in time is less than a desired data rate and as a result of the determining, move the surrogate so that the surrogate transmits data via the wireless control at a second non-zero data rate that is greater than or equal to the desired data rate at a second moment in time after the first moment in time.